README

my_robot_sim

目录结构

```
ros2_ws/
└── src/
    └── my_robot_sim/
        ├── package.xml
        ├── setup.py
        ├── setup.cfg
        ├── resource/
        │   └── my_robot_sim
        ├── my_robot_sim/
        │   ├── __init__.py
        │   ├── robot_monitor.py
        │   ├── wasd_controller.py
        │   ├── box_listener.py
        │   └── tf_listener.py
        ├── launch/
        │   ├── all_nodes.launch.py
        │   └── simulation.launch.py
        └── worlds/
            └── my_world.world
```
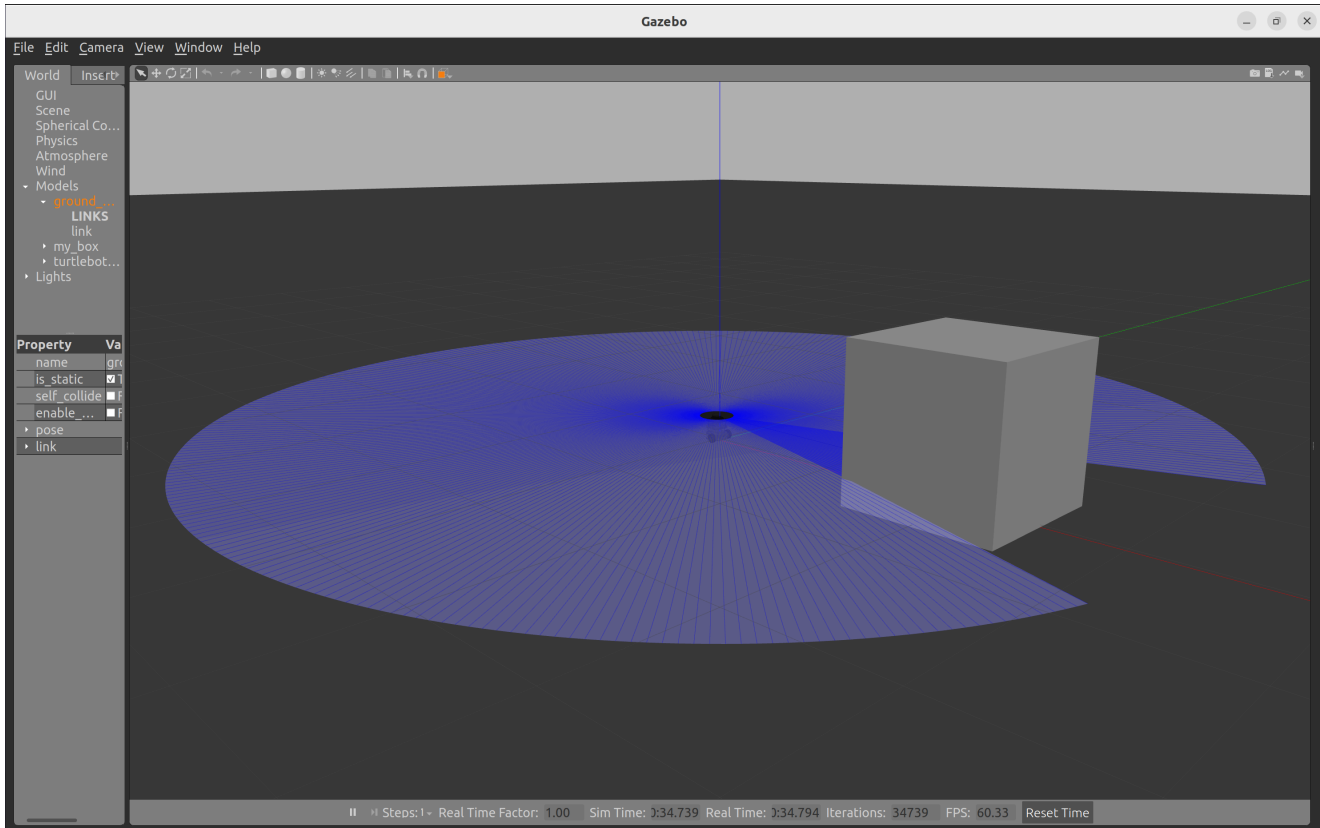
功能实现

- 启动Gazebo

```
# 编译
cd ~/ros2_ws
colcon build --packages-select my_robot_sim
source install/setup.bash
```

```
# 使用launch文件启动
ros2 launch my_robot_sim simulation.launch.py
```
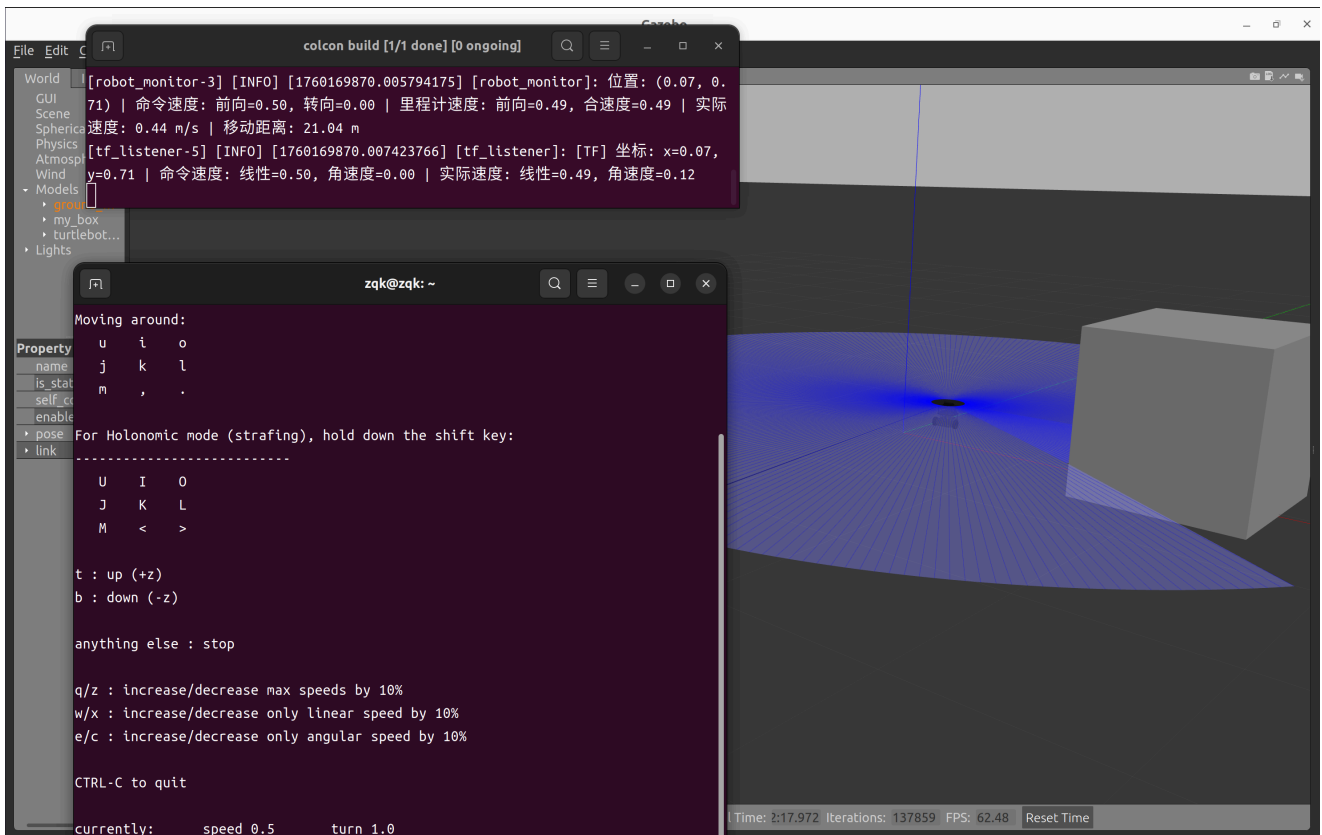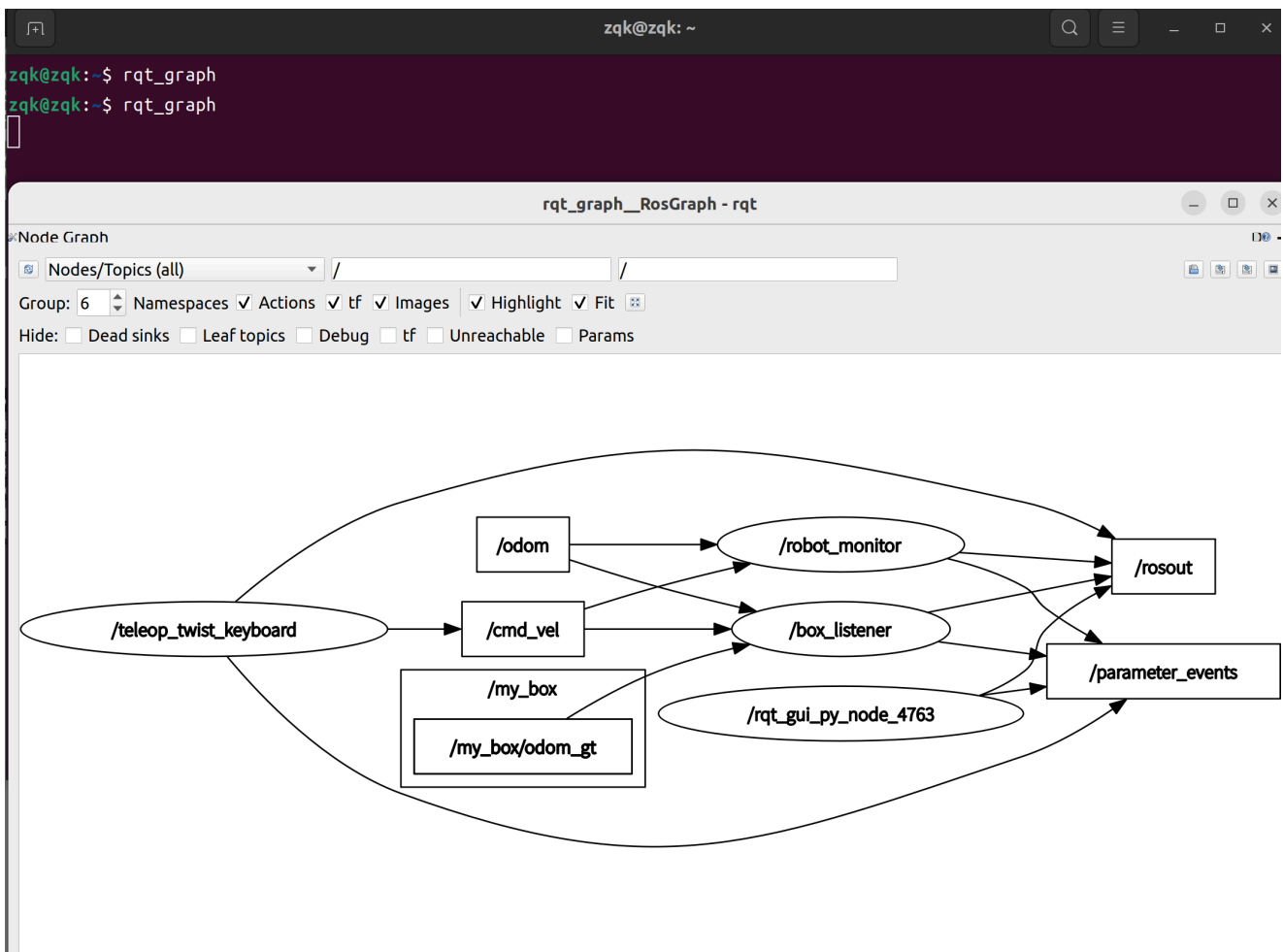

- 启用键盘控制

```
cd ~/ros2_ws
source install/setup.bash
ros2 run teleop_twist_keyboard teleop_twist_keyboard
```

- 查看话题关系

```
rqt_graph
```

- 使用rviz2可视化

```
rviz2
```